AMENDMENTS TO SPECIFICATION

Amend the paragraph added via Preliminary Amendment to page 1, line 1 before the first paragraph as follows:

CROSS REFERENCE TO RELATED APPLICATIONS

This application ~~claims the benefit of~~ is filed under 35 U.S.C. 371 as a national stage entry of PCT/IB 04/002020, filed June 17, 2004, which claims the benefit of U.S. provisional application serial no. 60/479,576 filed June 8, 2003 and U.S. provisional application serial no. 60/512,491 filed October 18, 2003, ~~both~~ each of which ~~are~~ is incorporated herein by reference.

Amend the paragraph beginning at page 7, line 24 and extending to page 8, line 7, of the filed application as follows:

With reference to FIGS. **2-4B**, and continuing reference to FIGURE **1**, in a preferred embodiment, the image-guided interventional medical procedure system **10** also includes a robotic arm **190** preferably carried on the stationary gantry **110**. The robotic arm **190** supports a remotely held needle guide apparatus **200** carrying an interventional implement or other like medical device **191** e.g., an ablation probe or a biopsy needle **192** at a desired location and trajectory. The medical device **191** is supported within the examination region **112** as shown. The robotic arm **190** is preferably a fully adjustable multi-jointed multi-segmented arm with each joint having at least one degree of freedom. As will be described in greater detail later herein, a medical device **191**, preferably the ablation probe or biopsy needle **192**, is held by the needle guide apparatus **200** (as best seen in FIGURE **3**). Accordingly, by appropriately arranging the robotic arm **190** (i.e., flexing or otherwise adjusting the multiple joints and/or segments, but preferably by executing a program which aligns the arm to the planned trajectory) and by appropriately positioning the subject **20** and the robotic arm **190** relative to one another, any arbitrary position and/or orientation of the biopsy needle **192** relative to the subject **20** is achieved as desired. Preferably, the position and/or orientation of the medical device **191** defines a physical path coincident with the virtual planned trajectory.